

What is claimed is:

1. A wall-climbing robot comprising:

- 5 (a) a chassis, said chassis comprising a topside and an underside;
- (b) a rotor attached to said chassis and rotatable with respect to the chassis, said rotor comprising a radial prominence;
- 10 (c) a foot attached to said prominence, said foot comprising means for adhering to a surface; and
- (d) an active drive means operatively connected to said rotor.

15 2. The wall-climbing robot of claim 1 further comprising an element attached to the underside of said chassis, said element comprising means for adhering to a surface.

20 3. The wall-climbing robot of claim 1 wherein said rotor further comprises a plurality of prominences.

25 4. The wall-climbing robot of claim 3 wherein said prominences are substantially equispaced around the rotor.

5. The wall-climbing robot of claim 3 further comprising a plurality of feet with a foot attached to each of said plurality of prominences.

30 6. The wall-climbing robot of claim 3, wherein said prominences are positioned at substantially equal radii around

the axis of the rotor.

7. The wall-climbing robot of claim 5, wherein said feet are positioned at substantially equal radii around the axis of the rotor.

8. The wall-climbing robot of claim 1, wherein said means for adhering is an adhesive.

9. The wall-climbing robot of claim 8, wherein said means for adhering is a pressure sensitive adhesive.

10. The wall-climbing robot of claim 8, wherein said means for adhering comprises an adhesive of polymerizing styrene, butadiene naphthenic oil, calcium carbonate, and hydrogenated polyterpene resin.

11. The wall-climbing robot of claim 1, wherein said rotor comprises a hub, a leg connected to said hub, and a foot connected to said leg.

12. The wall-climbing robot of claim 11, wherein said robot further comprises a plurality of legs and a plurality of feet.

13. The wall-climbing robot of claim 3, wherein a maximum of two prominences on said rotor are able to contact a surface at any time.

14. The wall-climbing robot of claim 5, wherein a maximum of two feet on said rotor are able to contact a

surface at any time.

15. The wall-climbing robot of claim 1 further
comprising a means for the remote control of said active drive
5 means.

16. The wall-climbing robot of claim 1 wherein a foot
contacts a surface over less than half of a revolution of the
rotor.

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17. A wall-climbing robot comprising:

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- (a) a chassis;
- (b) a first rotor attached to said chassis and
rotatable with respect to the chassis, said
first rotor comprising a first radial
prominence;
- (c) a second rotor attached to said chassis and
rotatable with respect to the chassis, said
second rotor comprising a second radial
prominence;
- (d) a first foot attached to said first radial
prominence, said first foot comprising means
for adhering to a surface, and a second foot
attached to said second radial prominence, said
second foot comprising means for adhering to a
surface; and
- (e) an active drive means operatively connected to
said first rotor and to said second rotor.

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18. The wall-climbing robot of claim 17, wherein the
means of adhering to a wall is adhesive.

19. The wall-climbing robot of claim 18, wherein the means of adhering to a wall is a pressure sensitive adhesive.

5 20. The wall-climbing robot of claim 18, wherein said means for adhering comprises an adhesive of polymerizing styrene, butadiene naphthenic oil, calcium carbonate, and hydrogenated polyterpene resin.

10 21. The wall-climbing robot of claim 17, wherein said first rotor comprises a first plurality of prominences and a first plurality of feet attached to said first plurality of prominences, and said second rotor comprises a second plurality of prominences and a second plurality of feet
15 attached to said second prominences.

22. A method of using the wall-climbing robot of claim 21, wherein no fewer than one foot on each of said first rotor and said second rotor contacts a surface at any time.

20 23. The wall-climbing robot of claim 21, wherein at least two feet of said first plurality of feet are able to contact a surface during a least a small arc of a revolution of said first rotor.

25 24. The wall-climbing robot of claim 23, wherein no more than two feet of the first plurality of feet contact a surface at any time.

30 25. The wall-climbing robot of claim 17 further comprising a means for the remote control of said active drive

means.

26. The wall-climbing robot of claim 19 further
comprising a means for the remote control of said active drive
5 means.

27. The wall-climbing robot of claim 21, wherein said
first plurality of prominences are equispaced around said
first rotor.

10 28. The wall-climbing robot of claim 27 wherein said
first plurality of feet are positioned at substantially equal
radii around the axis of the first rotor.

15 29. The wall-climbing robot of claim 17 further
comprising an axle attached to said chassis, wherein said
first rotor is attached proximate to an end of said axle.

20 30. The wall-climbing robot of claim 29 wherein said
second rotor is attached proximate to an end of said axle.

25 31. The wall-climbing robot of claim 17 further
comprising a skid mounted to said chassis able to contact a
surface.

32. The wall-climbing robot of claim 17 further
comprising a roller connected to said chassis able to contact
a surface.

30 33. The wall-climbing robot of claim 31, wherein said
skid is substantially remote from said first rotor.

34. The wall-climbing robot of claim 32, wherein said roller is substantially remote from said first rotor.

5 35. A wall-climbing robot comprising:

(a) a chassis;

10 (b) a first rotor attached to said chassis and rotatable with respect to the chassis, said first rotor comprising a first radial prominence;

(c) a second rotor attached to said chassis and rotatable with respect to the chassis, said second rotor comprising a second radial prominence;

15 (d) a first foot attached to said first radial prominence, said first foot comprising means for adhering to a surface, and a second foot attached to said second radial prominence, said second foot comprising means for adhering to a surface; and

20 (e) a first active drive means operatively connected to said first rotor, and a second active drive means operatively connected to said second rotor.

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36. The wall-climbing robot of claim 35, wherein the means of adhering to a wall is adhesive.

30 37. The wall-climbing robot of claim 36, wherein the means of adhering to a wall is a pressure sensitive adhesive.

38. The wall-climbing robot of claim 36, wherein said means for adhering comprises an adhesive of polymerizing styrene, butadiene naphthenic oil, calcium carbonate, and hydrogenated polyterpene resin.

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39. The wall-climbing robot of claim 35, wherein said first rotor comprises a first plurality of prominences and a first plurality of feet attached to said first plurality of prominences, and said second rotor comprises a second
10 plurality of prominences and a second plurality of feet attached to said second prominences.

40. A method of using the wall-climbing robot of claim 39, wherein no fewer than one foot on each of said first rotor
15 and said second rotor contacts a surface at any time.

41. The wall-climbing robot of claim 39, wherein at least two feet of said first plurality of feet are able to contact a surface during a least a small arc of a revolution
20 of said first rotor.

42. The wall-climbing robot of claim 41, wherein no more than two feet of the first plurality of feet contact a surface at any time.

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43. The wall-climbing robot of claim 35 further comprising a means for the remote control of said active drive means.

30 44. The wall-climbing robot of claim 37 further comprising a means for the remote control of said active drive

means.

45. The wall-climbing robot of claim 39, wherein said
first plurality of prominences are equispaced around said
5 first rotor.

46. The wall-climbing robot of claim 45 wherein said
first plurality of feet are positioned at substantially equal
radii around the axis of the first rotor.

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47. The wall-climbing robot of claim 35 further
comprising an axle attached to said chassis, wherein said
first rotor is attached proximate to an end of said axle.

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48. The wall-climbing robot of claim 47 wherein said
second rotor is attached proximate to an end of said axle.

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49. The wall-climbing robot of claim 35 further
comprising a skid mounted to said chassis able to contact a
surface.

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50. The wall-climbing robot of claim 35 further
comprising a roller connected to said chassis able to contact
a surface.

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51. The wall-climbing robot of claim 49, wherein said
skid is substantially remote from said first rotor.

52. The wall-climbing robot of claim 50, wherein said
roller is substantially remote from said first rotor.